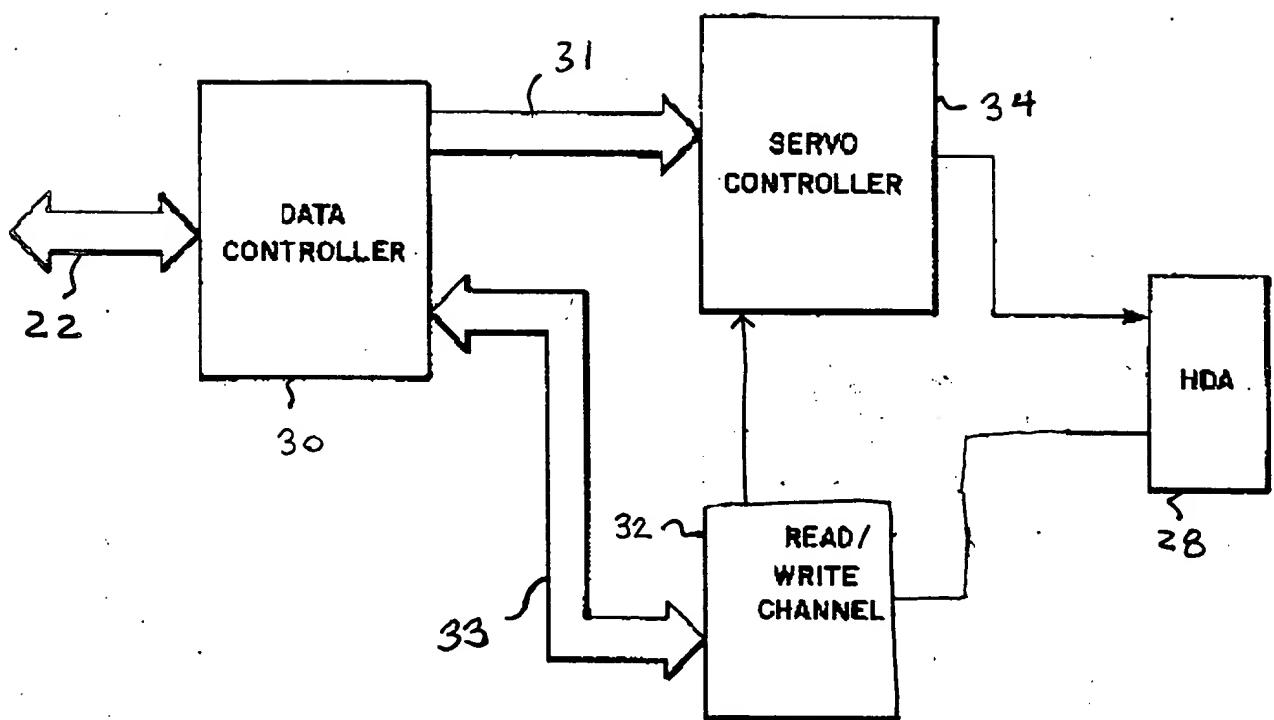


FIG. 1



26

FIG. 2

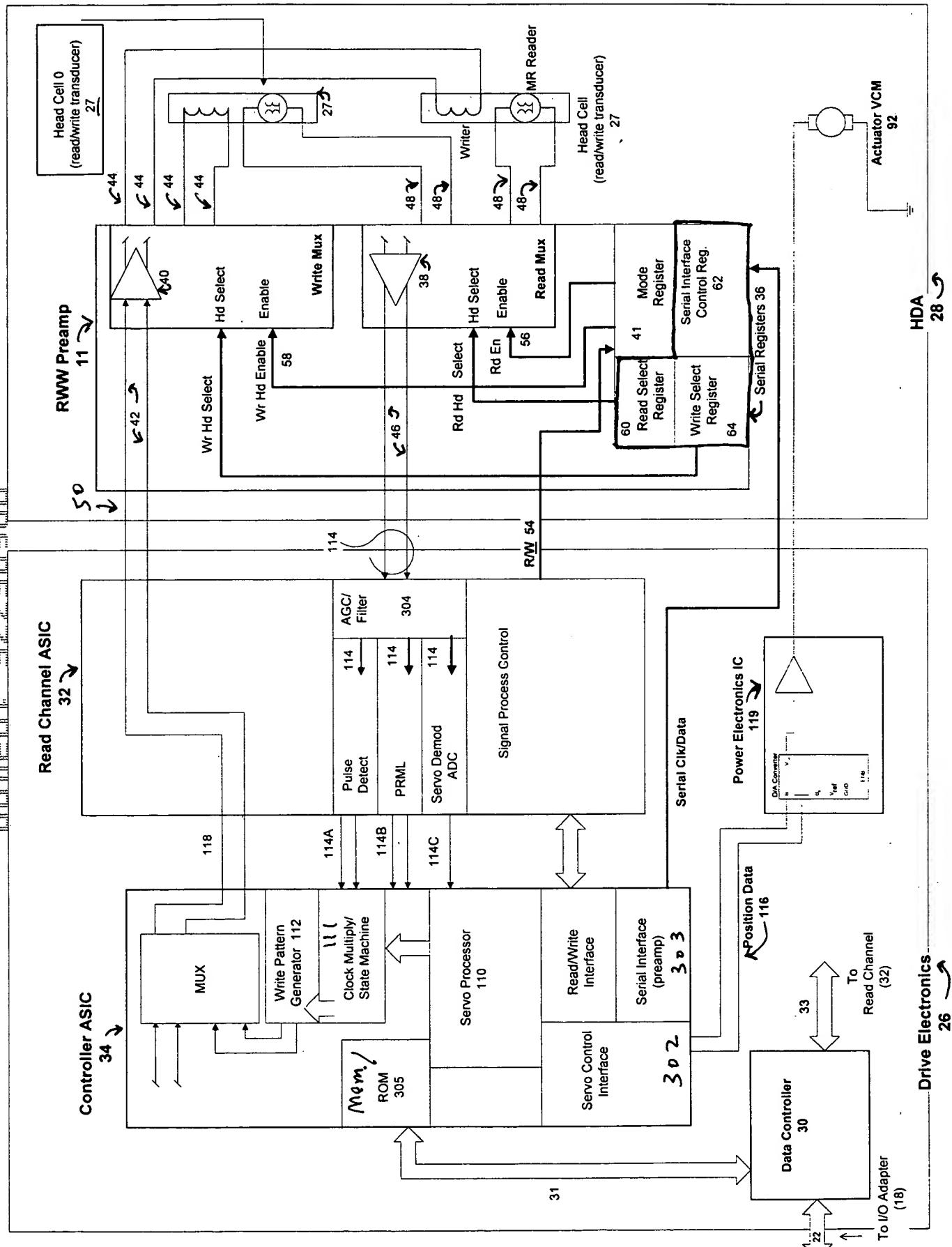


Fig. 3

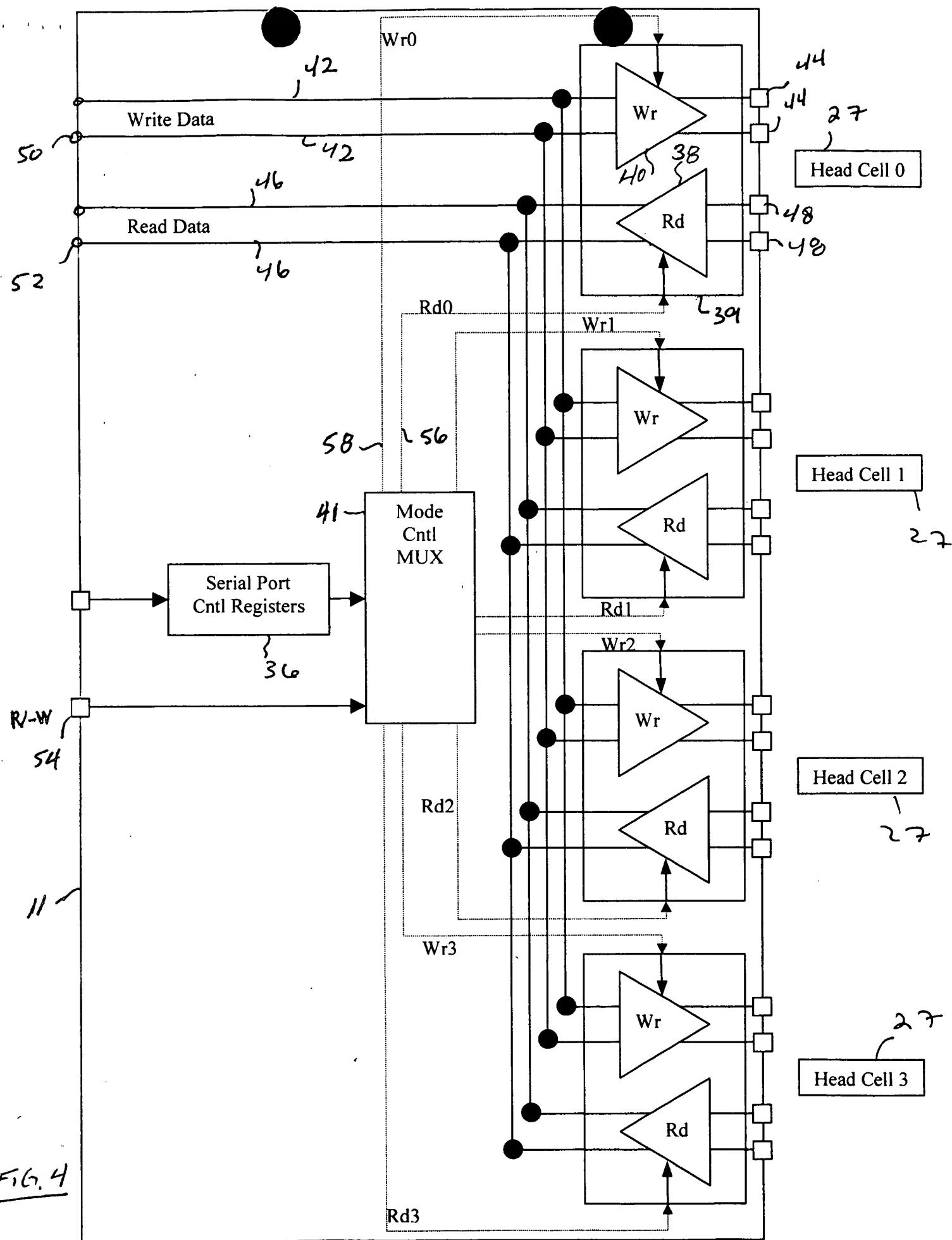


FIG. 4

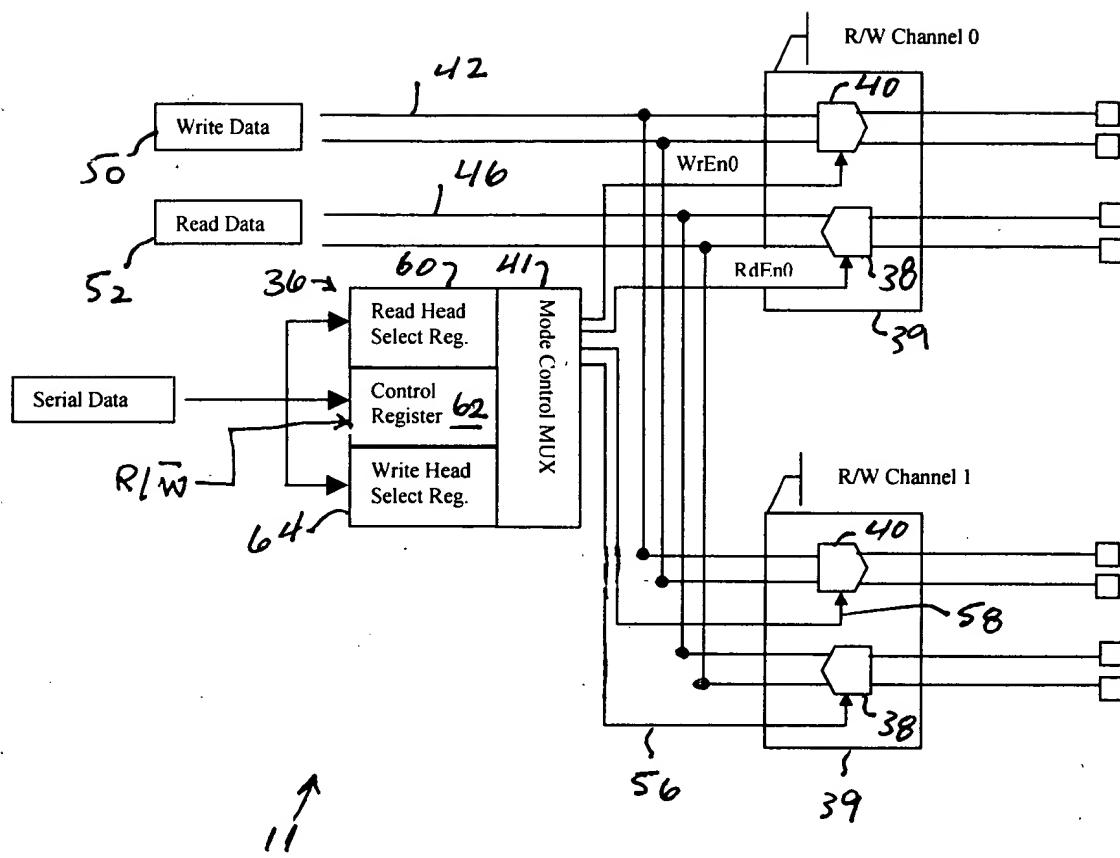


Fig. 5

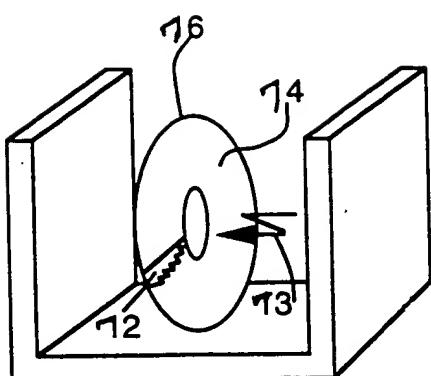


FIG. 6

↑ 10

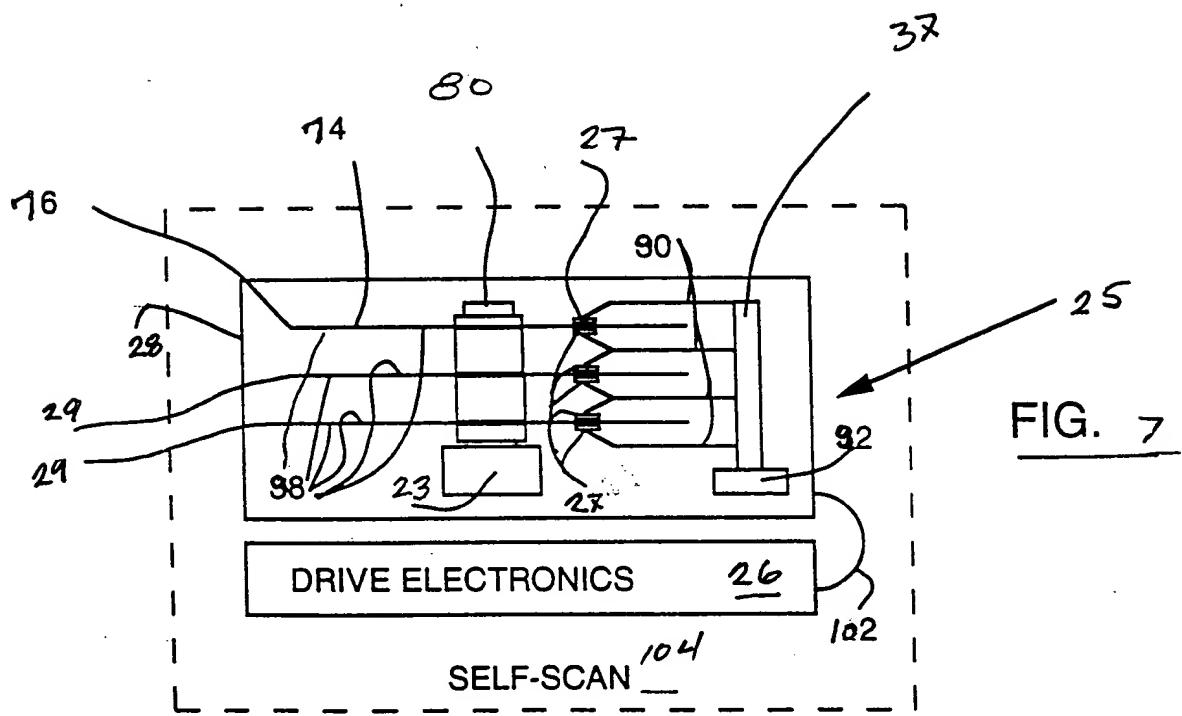
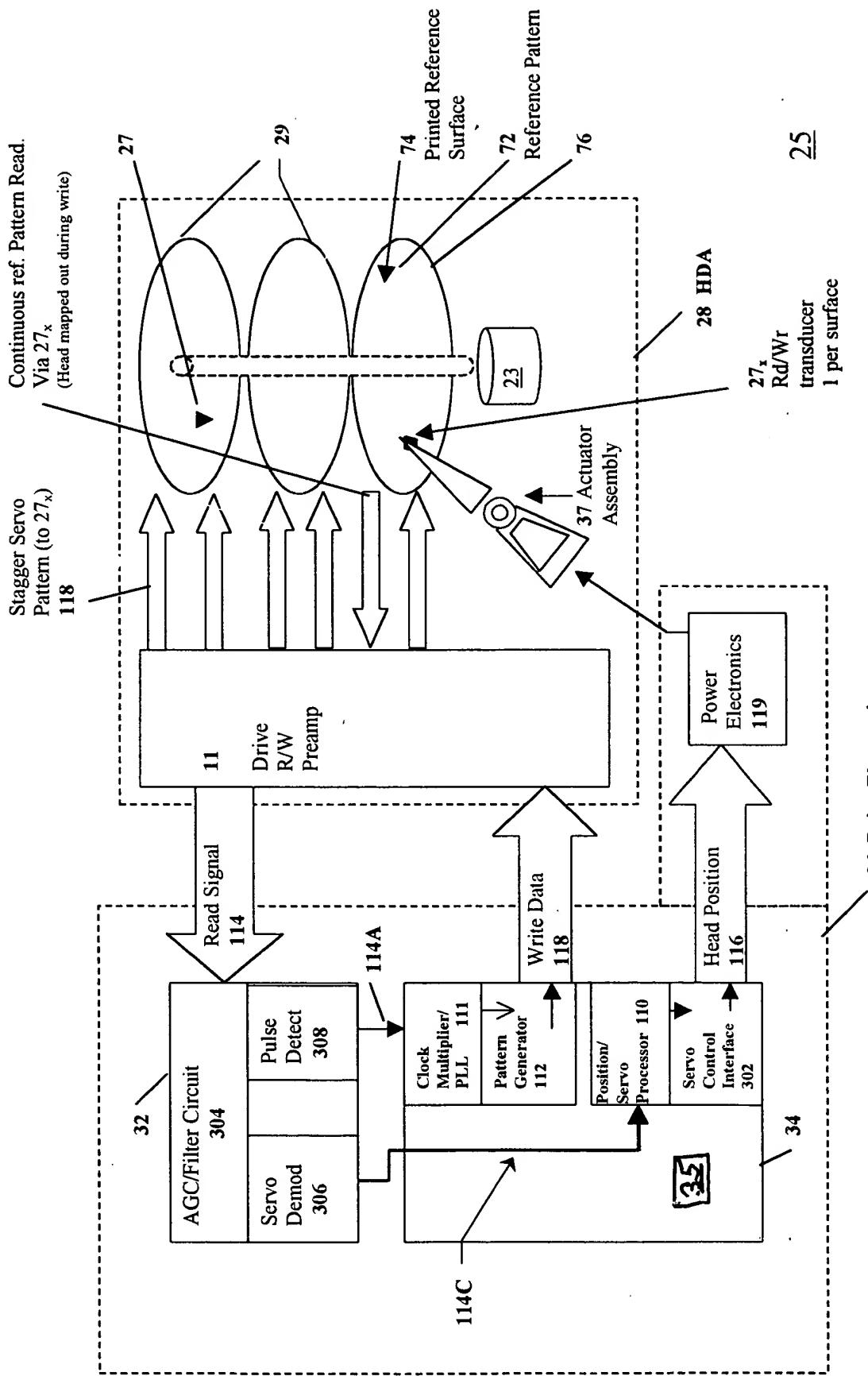
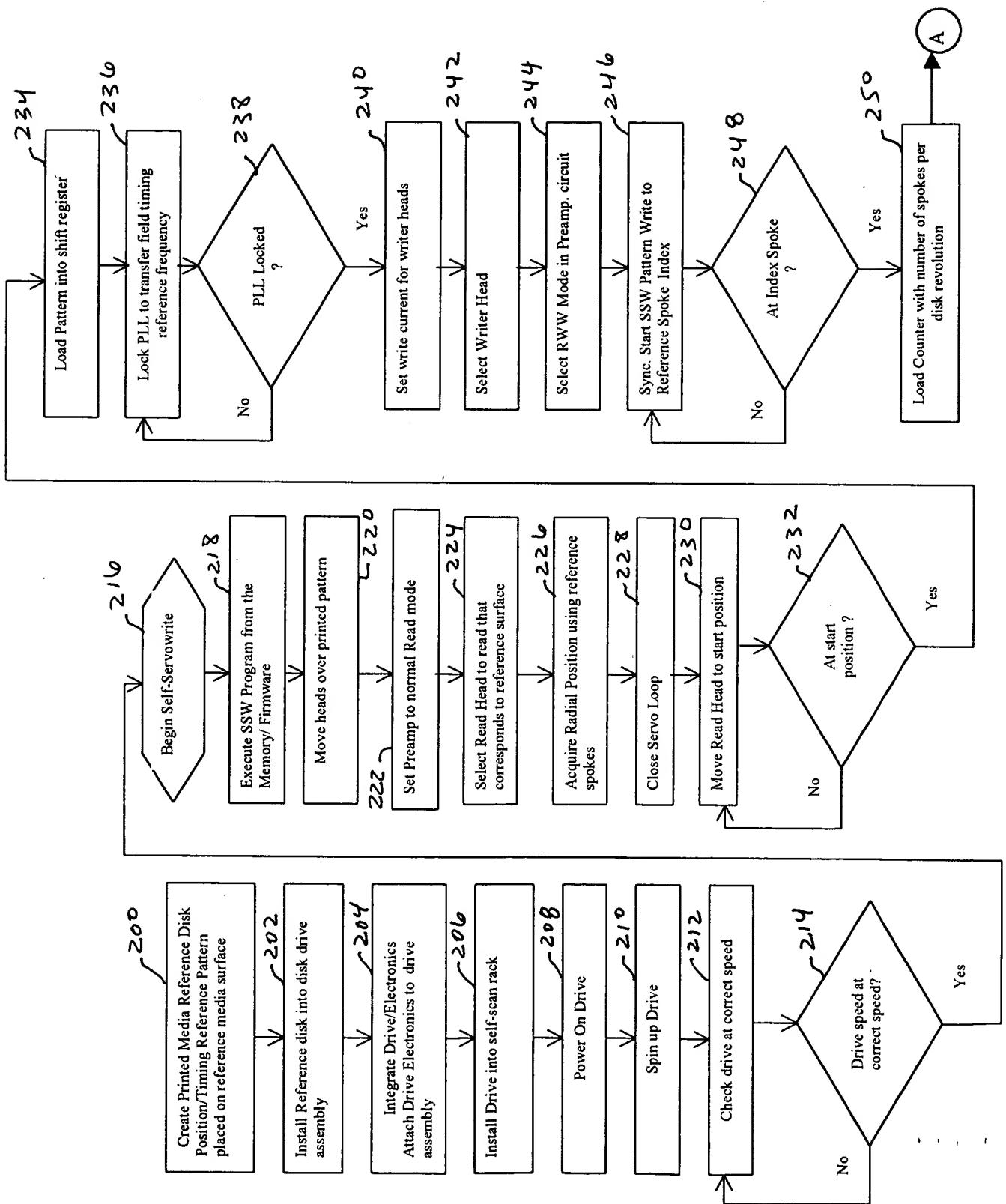


FIG. 7

FIG. 8



F1 C7. QA



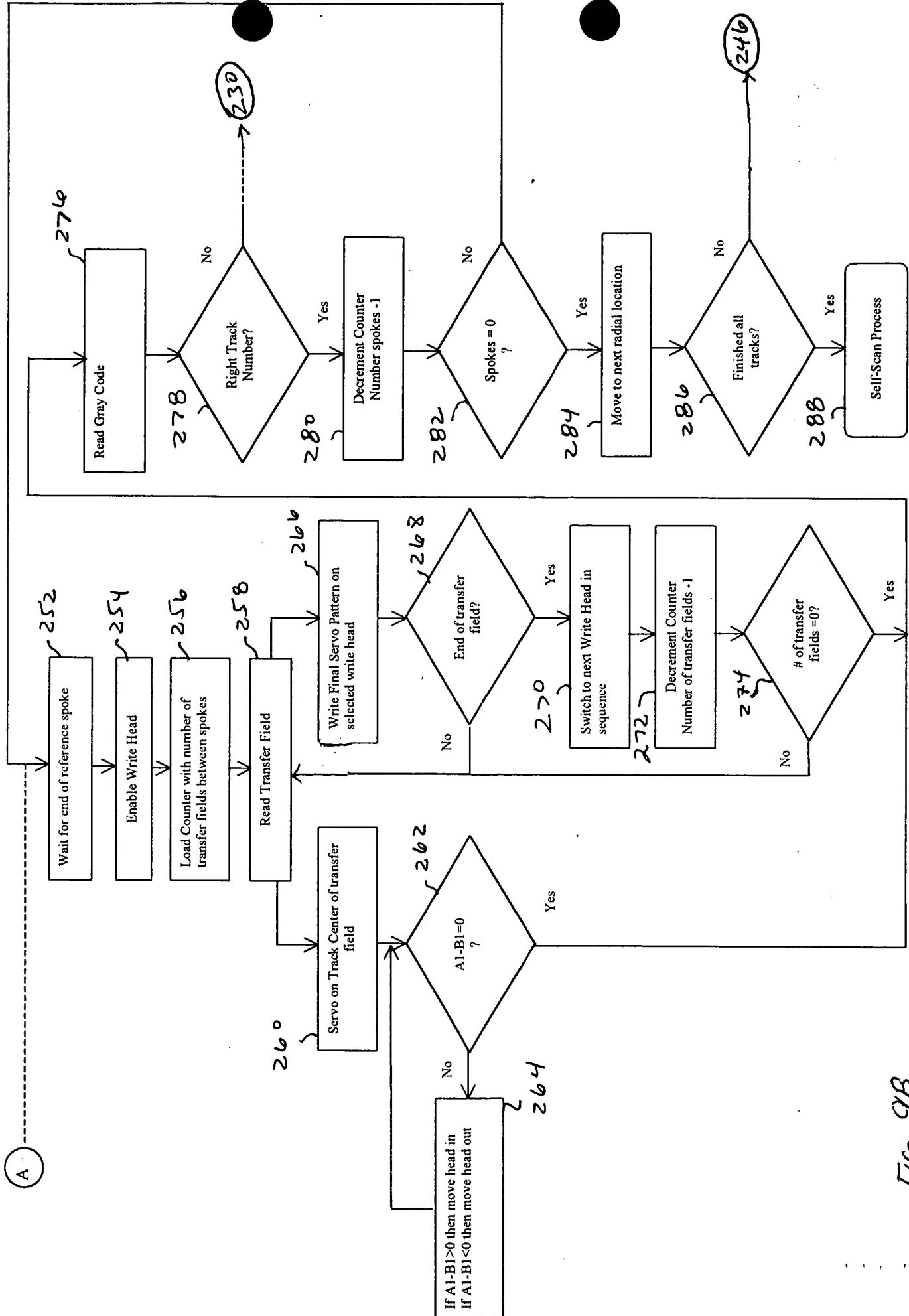


FIG. 9B

Head Position Control Flow Diagram

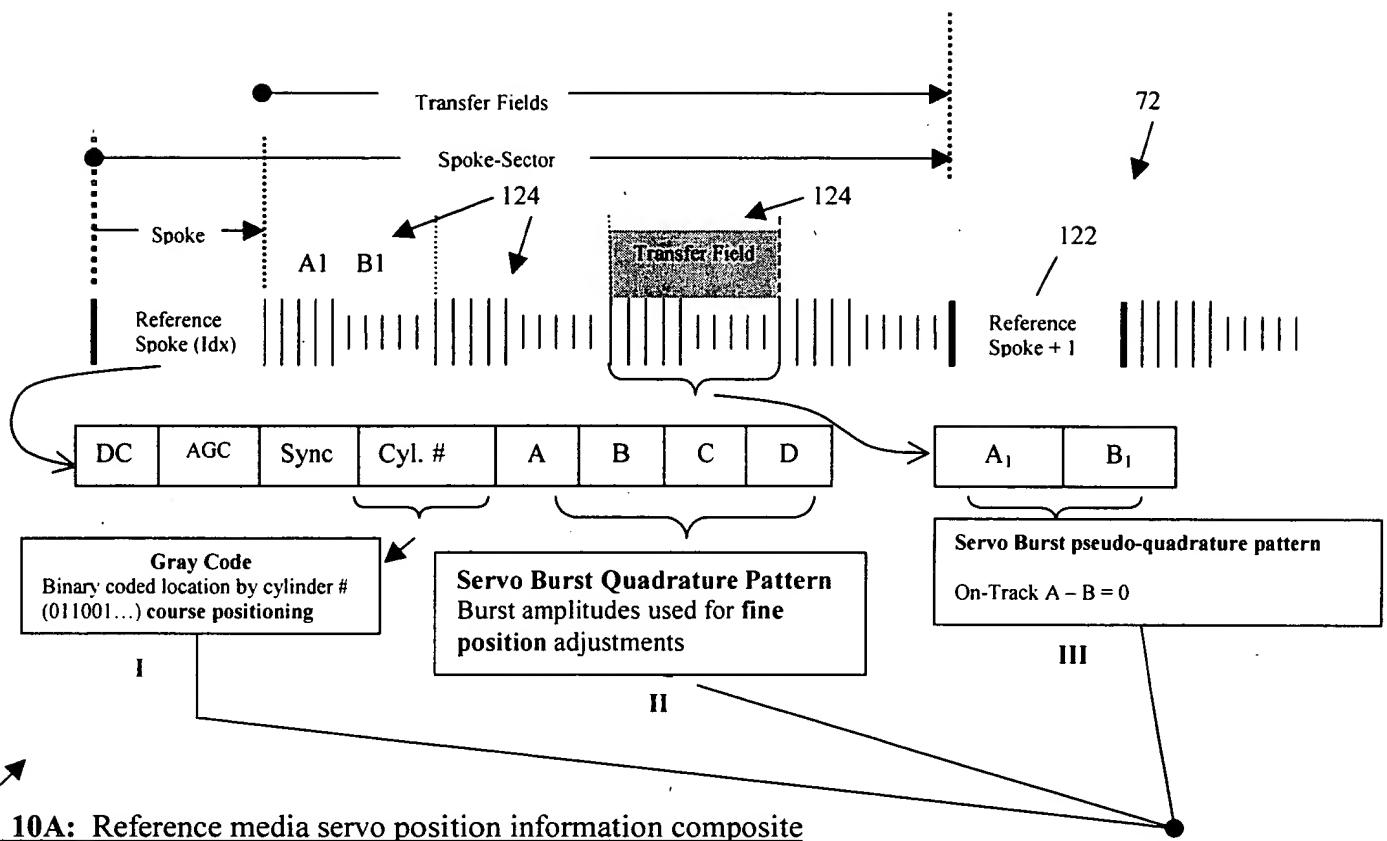
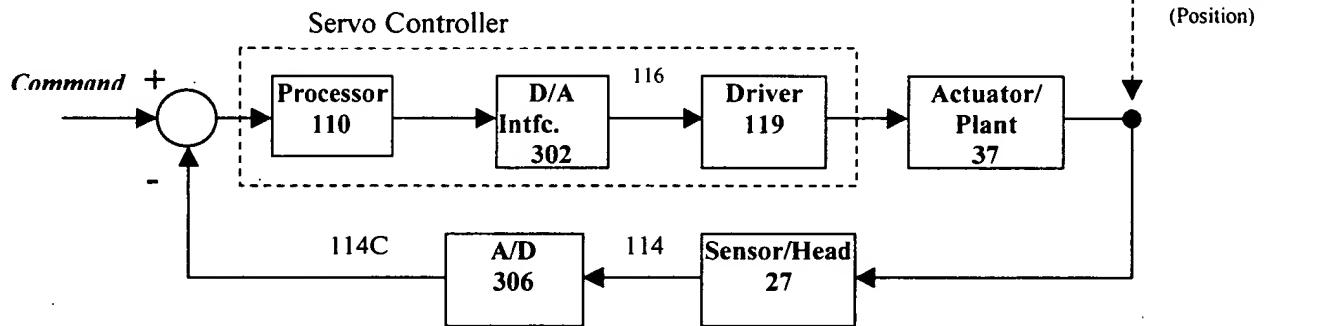


FIG. 10A: Reference media servo position information composite



Position mode vs. Sense/head data used: (see fig. 10A I, II & III)

I – Course Position (Seek)

I, II – Track Following (On-track, Short Seek)

I, II & III – High Bandwidth Track Following (RWW self-servowrite)

FIG. 10B Position Control Feedback Loop

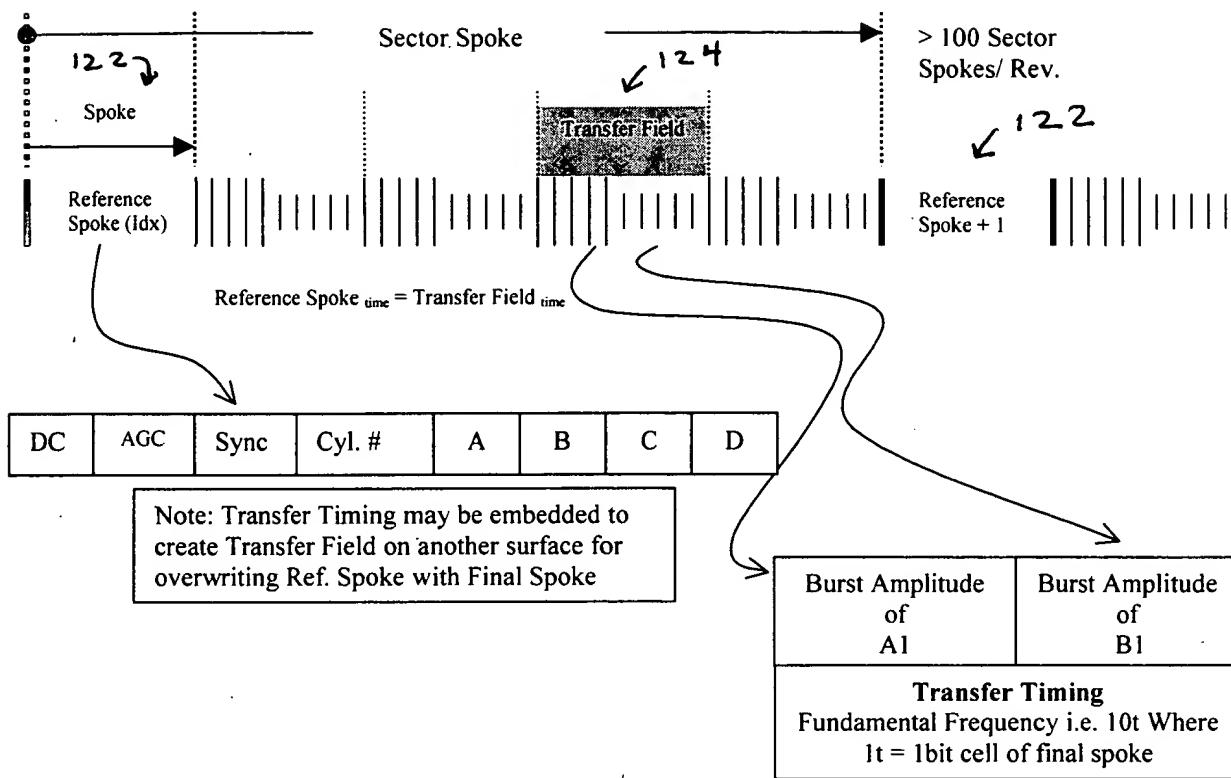


FIG. 10 C

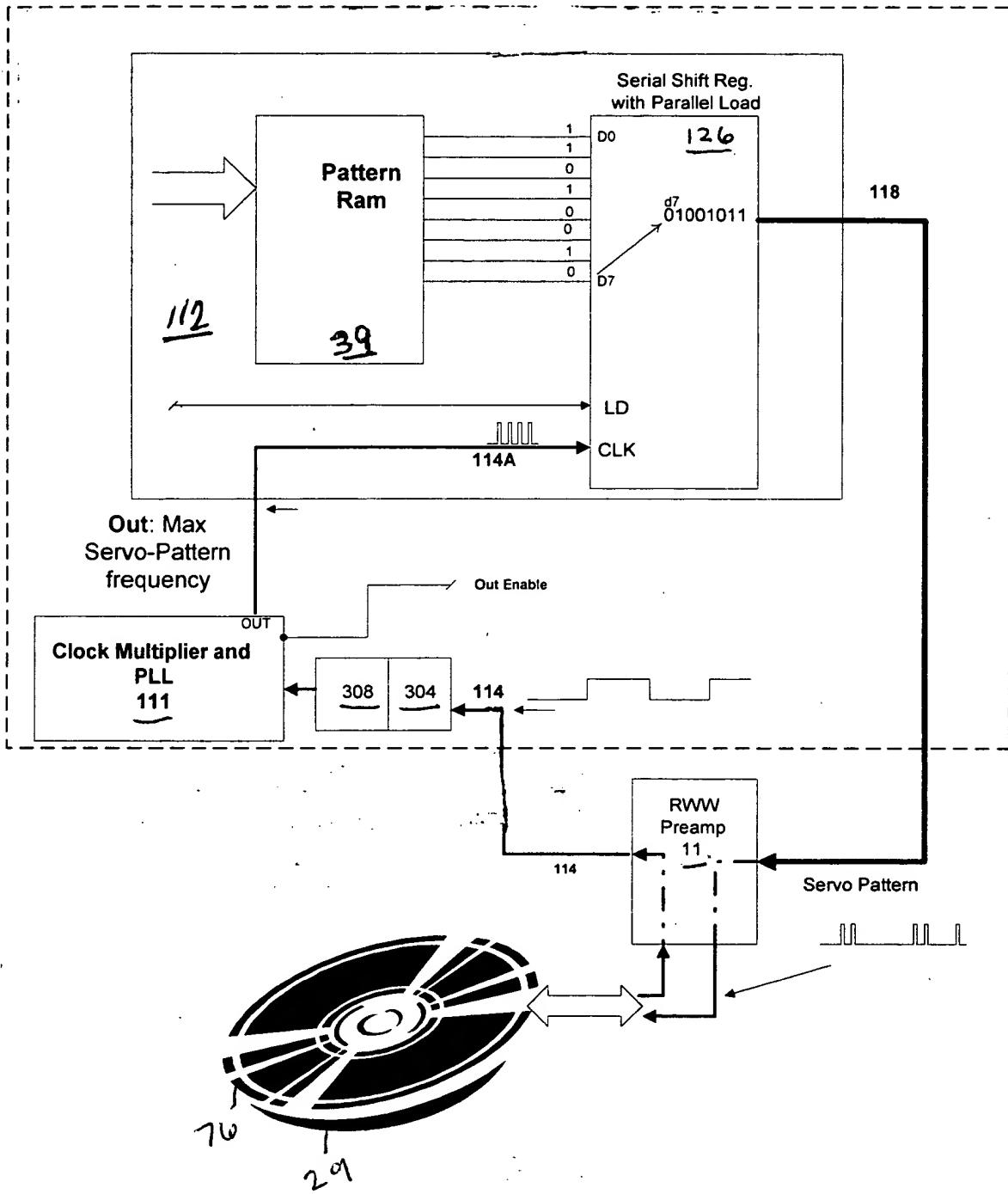
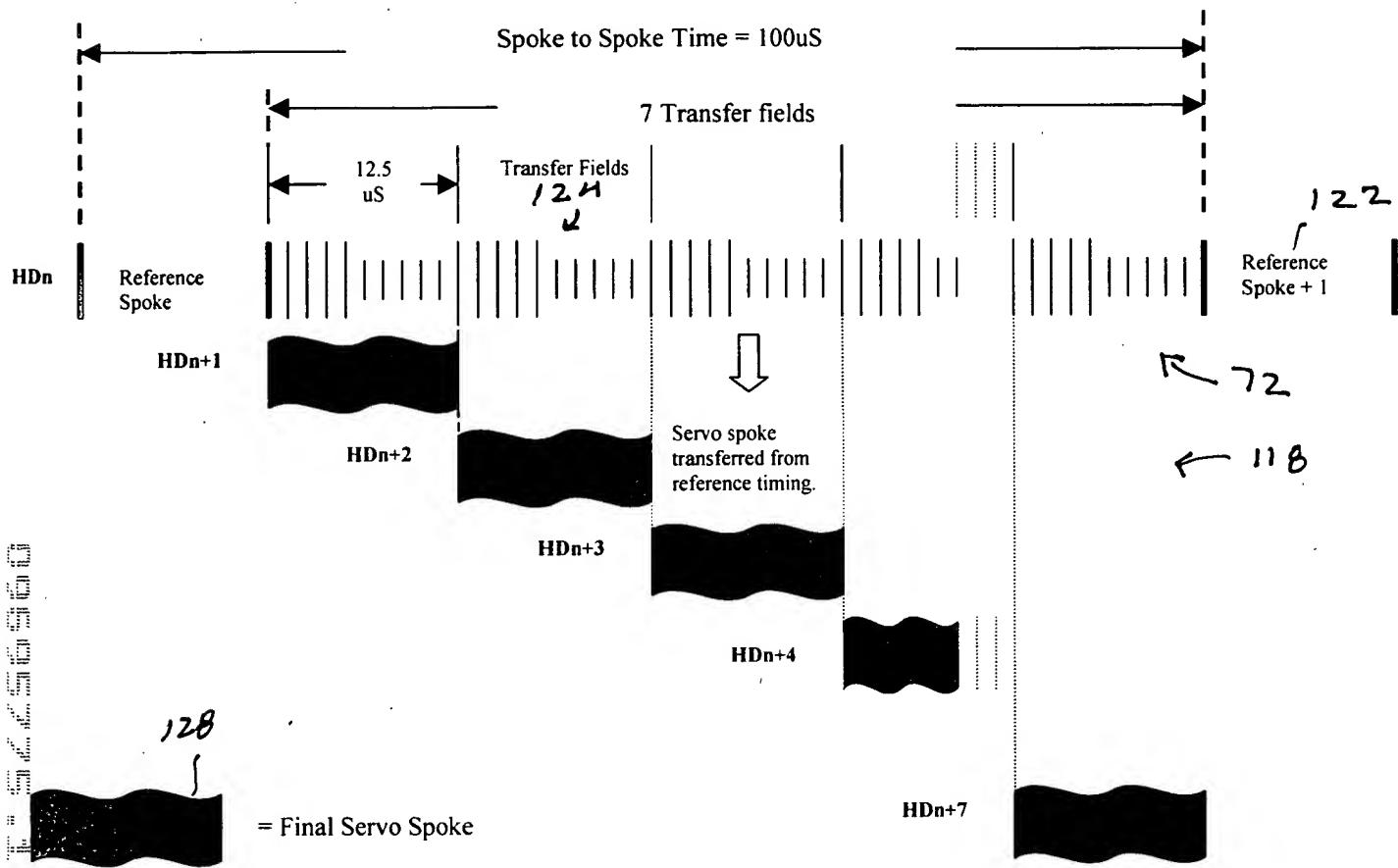


Fig. 11

Media Reference Pattern and Final Spoke Transfer Reference Surface (HDn)



This example is based on drive rotational speed at 6000 rpm, and 100 spokes per revolution.

6000 rpm = 10 mS per revolution.

10mS/100sectors = 100uS per sector.

1 sector = spoke + data field.

1 spoke = sector/8 (for 8 head stagger) = 12.5uS per spoke

1 spoke(Tt) = 1 transfer field(Tt)

spoke transition(t) = transfer field transition(t)/x

➤ Tt = total time

➤ t = time

Fig. 12

Self-Reprocess using RWW

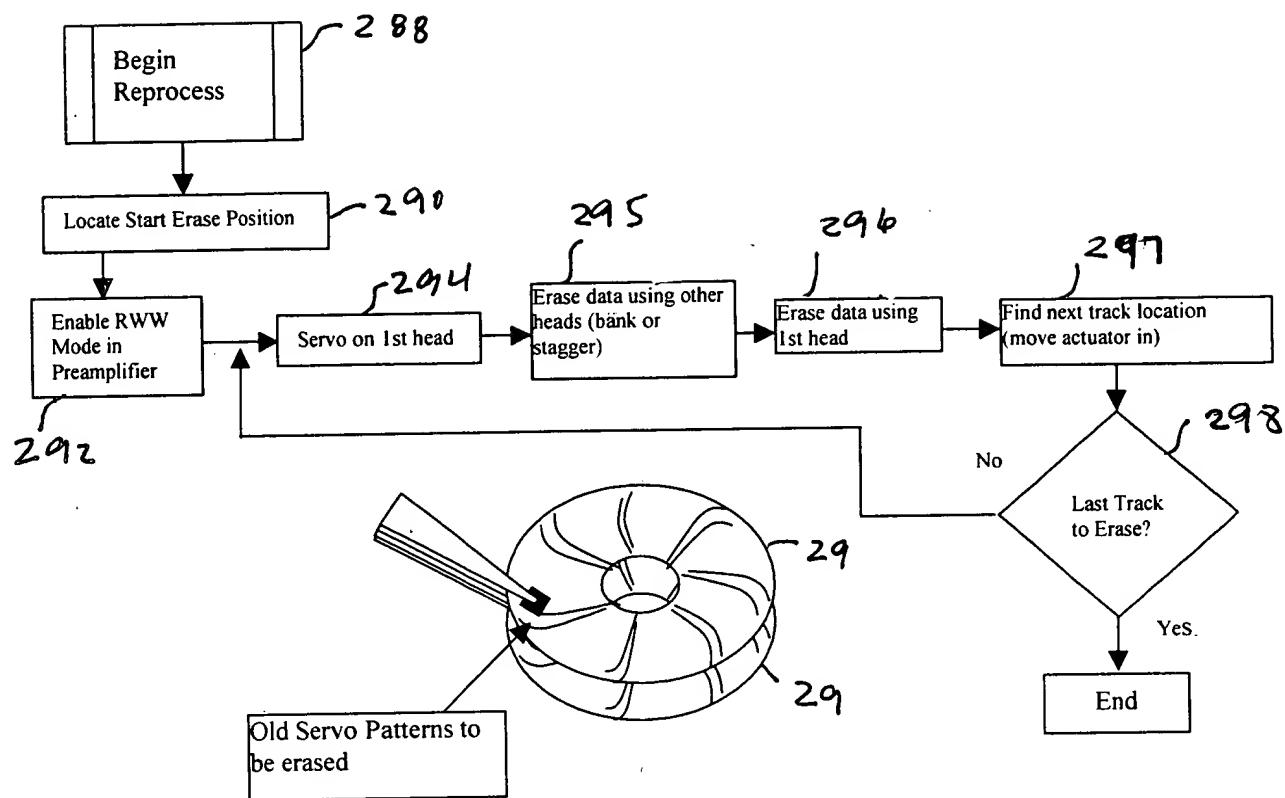


FIG. 13